

**IN THE CLAIMS:**

Please amend claims 1-7 as follows.

1. (Currently Amended) A joint structure ~~of a robot for actuating an assembly being to be~~ connected to an assembly and a robot-link of a robot, the joint structure comprising:

a first motor ~~for causing the~~ configured to cause the assembly to swing in a longitudinal swing-motion with respect to the ~~robot-link~~; and

a second motor ~~for causing~~ configured to cause the assembly to swing in a lateral swing-motion with respect to the ~~robot-link~~, wherein

the first motor and the second motor are disposed so that the output shaft of the first motor and the output shaft of the second motor are ~~in~~-parallel with each other and are orthogonal to the ~~robot-link~~.

2. (Currently Amended) A joint structure of a robot according to claim 1 further comprising:

a third motor ~~for causing~~ configured to cause a rotary motion of the assembly a ~~rotary motion~~-with respect to the ~~robot-link~~, wherein

the output shaft of the third motor is shifted by a predetermined amount with respect to ~~the a~~ central axis of the rotary motion.

3. (Currently Amended) A joint structure of a robot according to claim 1, ~~of~~  
~~claim 2~~ further comprising:

a movable cover ~~being configured to be~~ rotatable with respect to at least one of the  
assembly and the ~~robot~~-link, and

an elastic member ~~generating configured to generate~~ a force between the movable  
cover and at least one of the assembly and the ~~robot~~-link, and ~~placing-place~~ the movable  
cover at a predetermined position.

4. (Currently Amended) A joint structure of a robot according to claim 1, ~~of~~  
~~claim 2~~ further comprising:

a first rotary unit ~~being-is~~ connected to the assembly;

a second rotary unit ~~supporting-configured to support~~ the first rotary unit while  
allowing the rotation around a first axis of the first rotary unit; and

a base ~~supporting-configured to support~~ the second rotary unit while allowing the  
rotation around a second axis orthogonal to ~~the-a~~ first axis of the second rotary unit,  
wherein

the first motor and the second motor are disposed on the base.

5. (Currently Amended) A joint structure of a robot according to claim 4  
further comprising:

a first swing lever ~~which~~ is connected to an output shaft of the first motor, and ~~changes-configured to change~~ the rotation of the output shaft of the first motor into a reciprocating motion;

a joint ~~which~~ is connected to the first swing lever and the first rotary unit, and ~~transfers-configured to transfer~~ the reciprocating motion to the first swing lever to rotate the first rotary unit around the first axis;

a second swing lever ~~which~~ is connected to an output shaft of the second motor, and ~~changes-configured to change~~ a rotary motion of the output shaft of the second motor into a reciprocating motion; and

a rod which is connected to the second swing lever and the second rotary unit, and ~~transfers-configured to transfer~~ the reciprocating motion to the second rotary unit to rotate the second rotary unit around the second axis.

6. (Currently Amended) A joint structure of a robot according to claim 4 further comprising:

a motor side pulley ~~which~~ is connected to an output shaft of the third motor;

a driven pulley ~~which~~ is connected to the base and ~~rotates-configured rotate~~ the base around the central axis of the rotary motion; and

a belt ~~which transfers-configured to transfer~~ the rotation of the motor side pulley to the driven pulley.

7. (Currently Amended) A joint structure of a robot according to claim 5 further comprising:

a motor side pulley ~~which~~ is connected to an output shaft of the third motor;

a driven pulley ~~which~~ is connected to the base and ~~rotates~~ configured to rotate the base around the central axis of the rotary motion; and

a belt ~~which transfers~~ configured to transfer the rotation of the motor side pulley to the driven pulley.

8. (Original) A joint structure of a robot according to claim 3, wherein

a contact face to which the elastic member is contactable is formed on the movable cover, and

a stopper, which contacts with the elastic member to control the range of the rotation around the central axis of the rotary motion of the movable cover, is provided at an inside periphery of the movable cover.